

## **IN THE CLAIMS:**

Please amend claim 1 as follows.

1. (Currently Amended) A leg type mobile robot comprising:

a body;

legs each connected to the body via a first joint; and

feet, each connected to an end part of the leg via a second joint, wherein each foot includes

at least one foot portion, which has a ground area to be grounded on a floor surface at a bottom thereof, and

a floor reaction force detector configured to detect a floor reaction force acting from a floor surface through the foot portion, and wherein

in a plane view, when the robot is in a standing-still state,

a center of the second joint is offset against a position ~~in a plane view,~~

the position is the position ~~where a distance to a remotest point of at least one ground area becomes minimum~~ in the ground area and has an equal distance to each remotest point of the ground area, and

a center of the floor reaction force detector is closer to the position than to the center of the second joint ~~in a plane view.~~

2. (Previously Presented) A leg type mobile robot according to claim 1, wherein

the center of the floor reaction force detector is offset to a rear direction with respect to the position.

3. (Previously Presented) A leg type mobile robot according to claim 2, wherein the center of the floor reaction force detector is positioned on a line segment connecting the position and the center of the second joint.

4. (Previously Presented) A leg type mobile robot according to claim 1, wherein the center of the floor reaction force detector is offset to a rear direction in a center side of the leg type mobile robot with respect to the position.

5. (Previously Presented) A leg type mobile robot according to claim 4, wherein the center of the floor reaction force detector is located on the perpendicular taken down from the center of the second joint to the line segment extended from the position to a rear direction.

6. (Previously Presented) A leg type mobile robot according to claim 4, wherein the center of the floor reaction force detector is located on the perpendicular taken down from the center of the second joint to the line segment extended from the position to a center of the leg type mobile robot.

7. (Previously Presented) A leg type mobile robot according to claim 4, wherein the center of the floor reaction force detector is positioned on a line segment connecting the position and the center of the second joint.